

Figure 1.

PRIOR ART

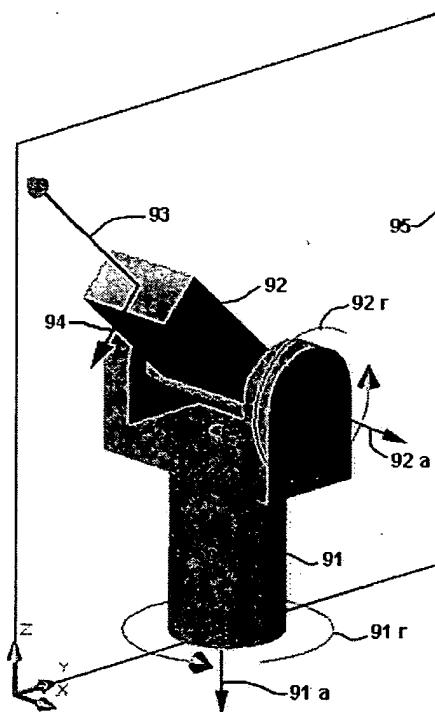


Figure 2

PRIOR ART

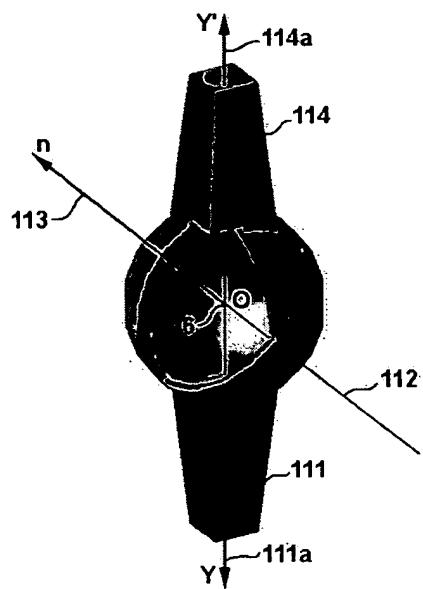


Figure 3a

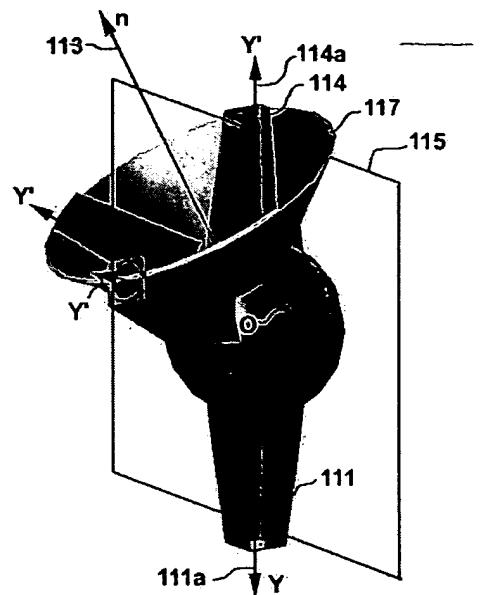


Figure 3b

PRIOR ART

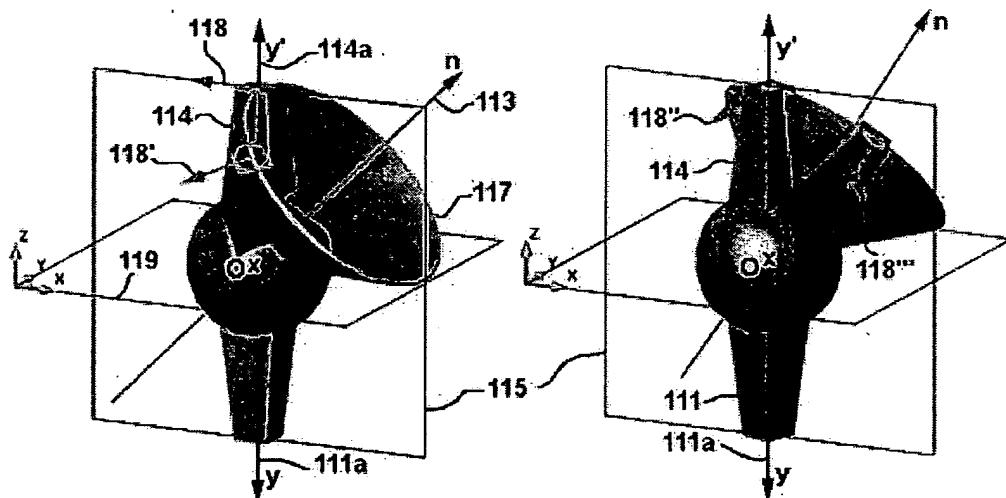


Figure 4a

Figure 4b

PRIOR ART

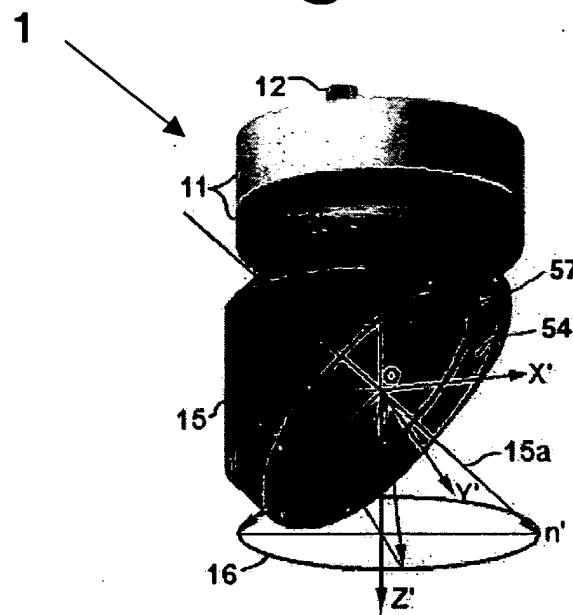


Figure 5a

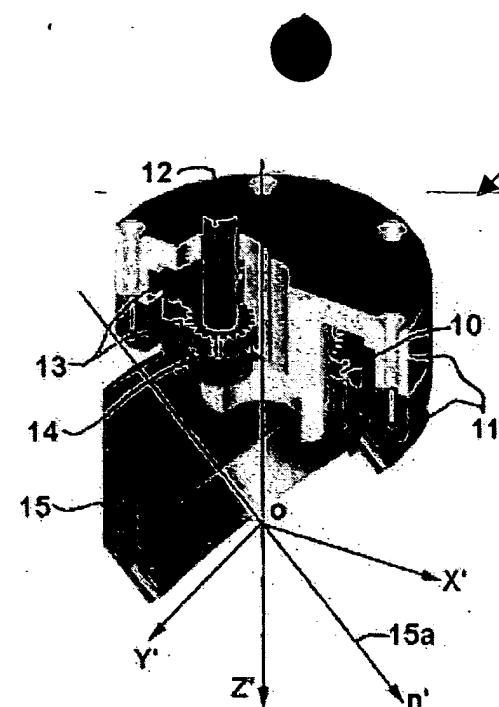


Figure 5b

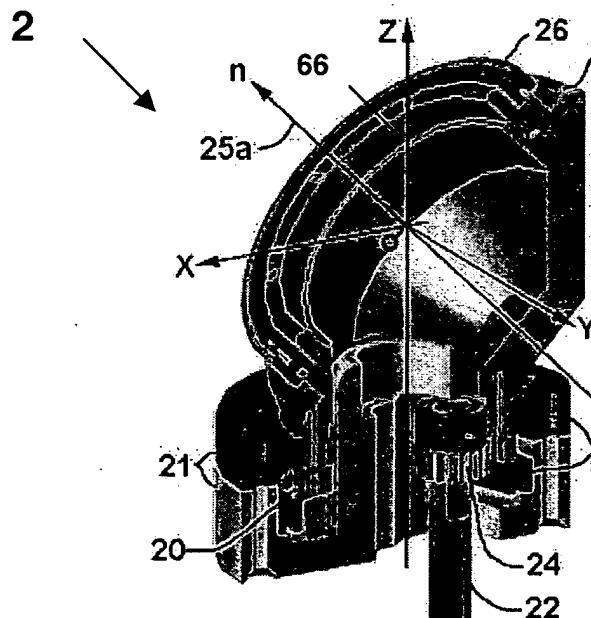


Figure 6a

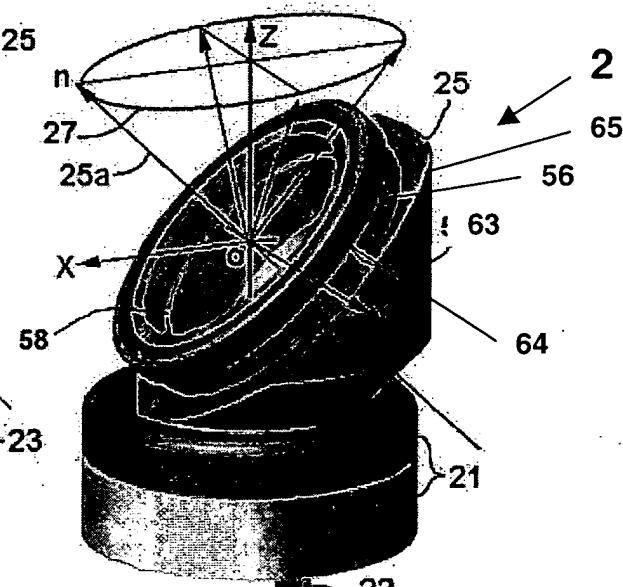


Figure 6b

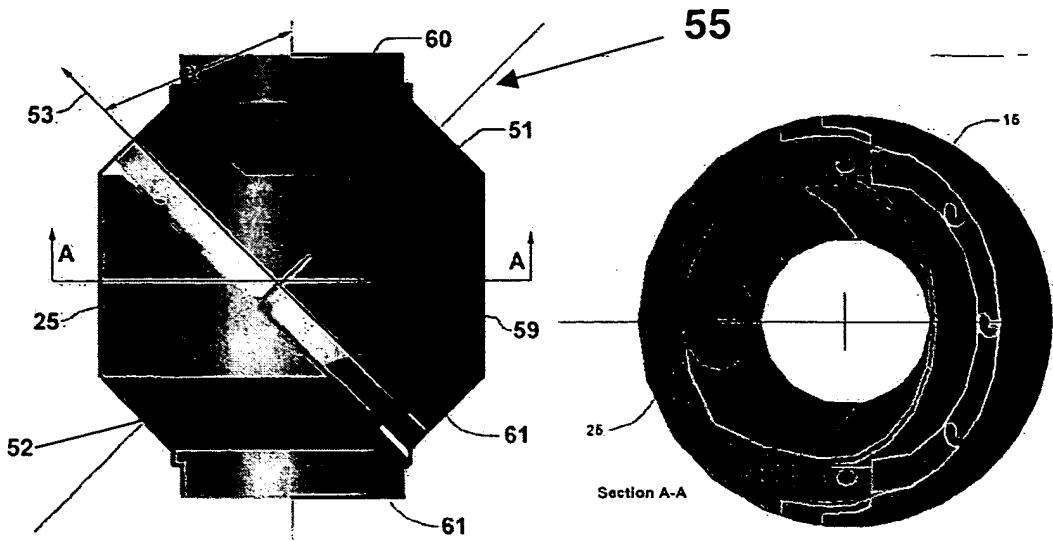


Figure 7a

Figure 7b

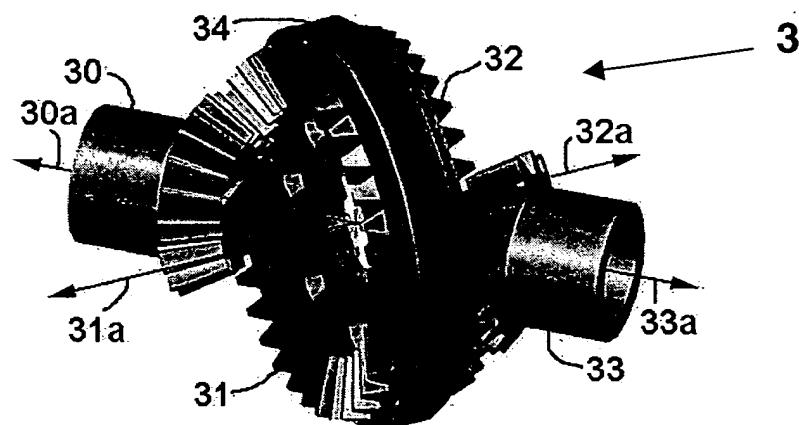


Figure 8

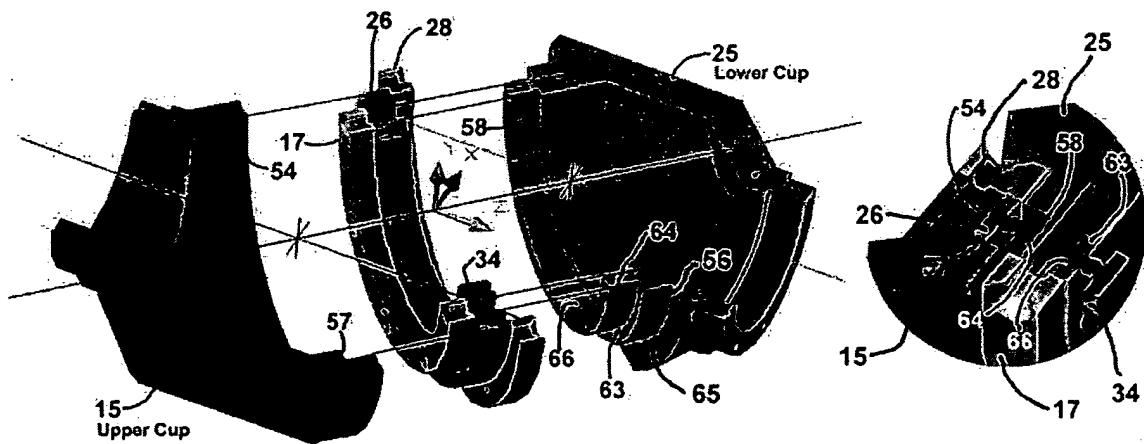


Figure 9a

Figure 9b

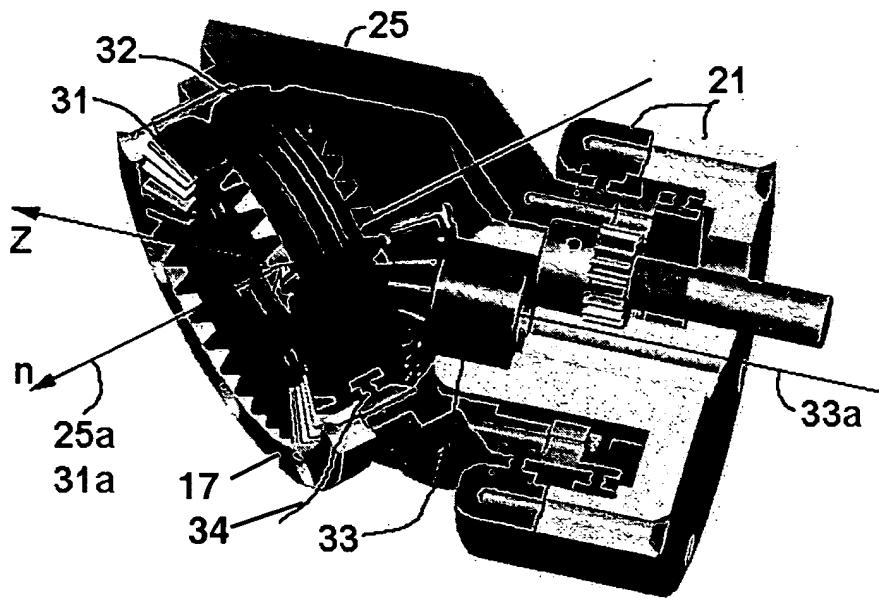


Figure 10

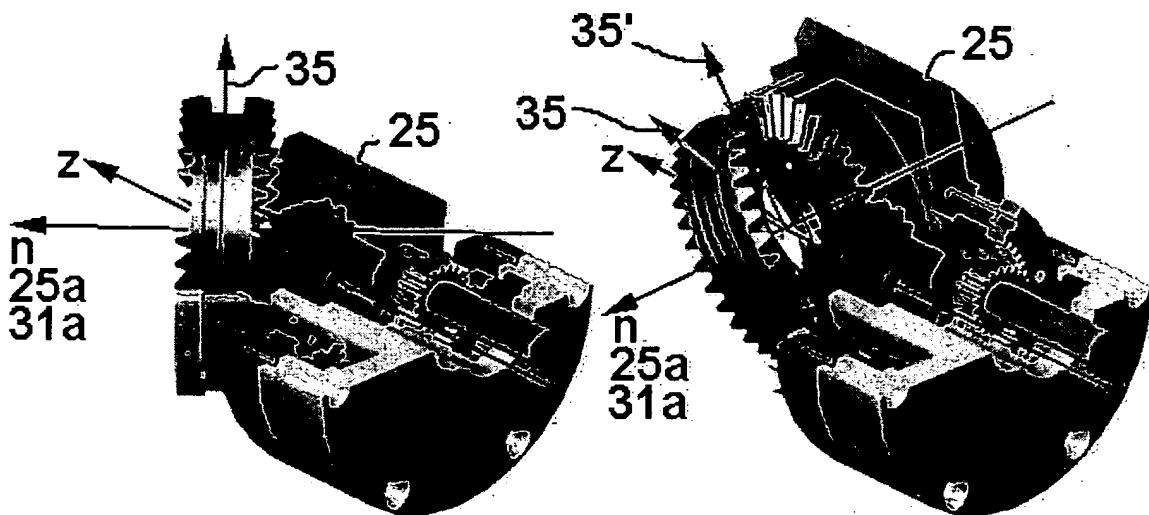


Figure 11a

Figure 11b

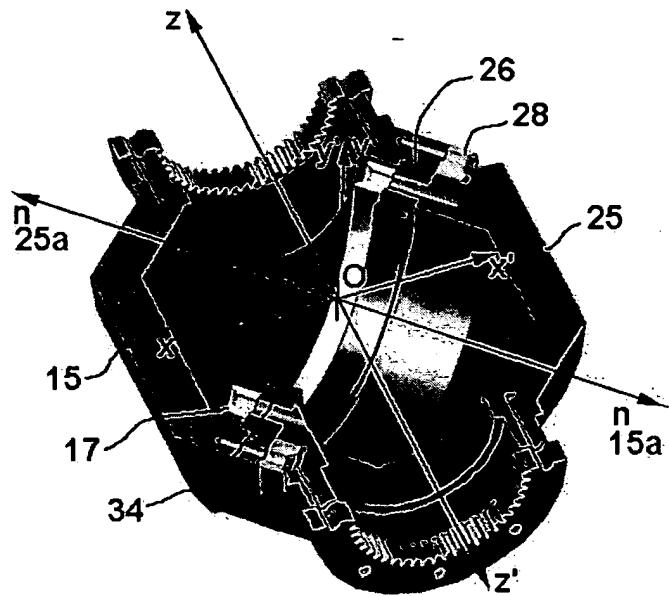


Figure 12

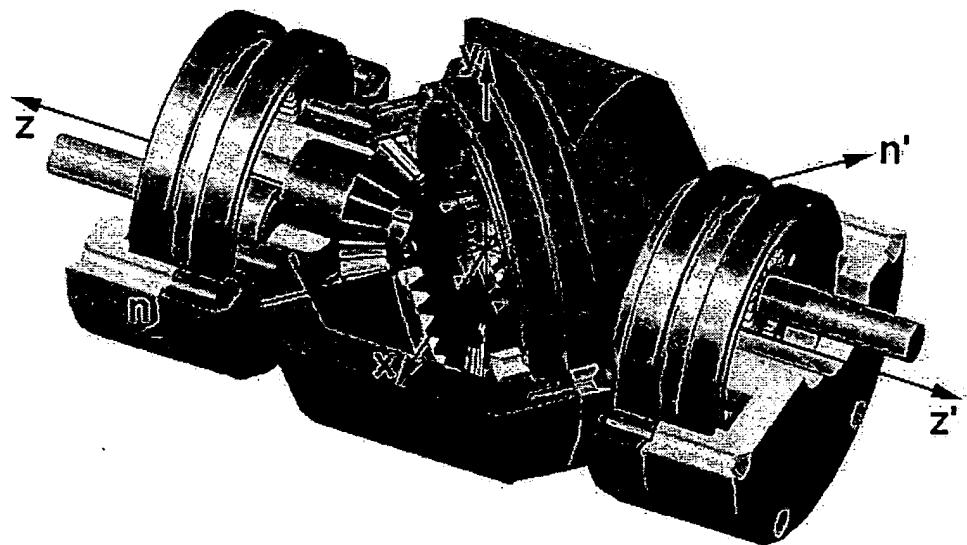


Figure 13

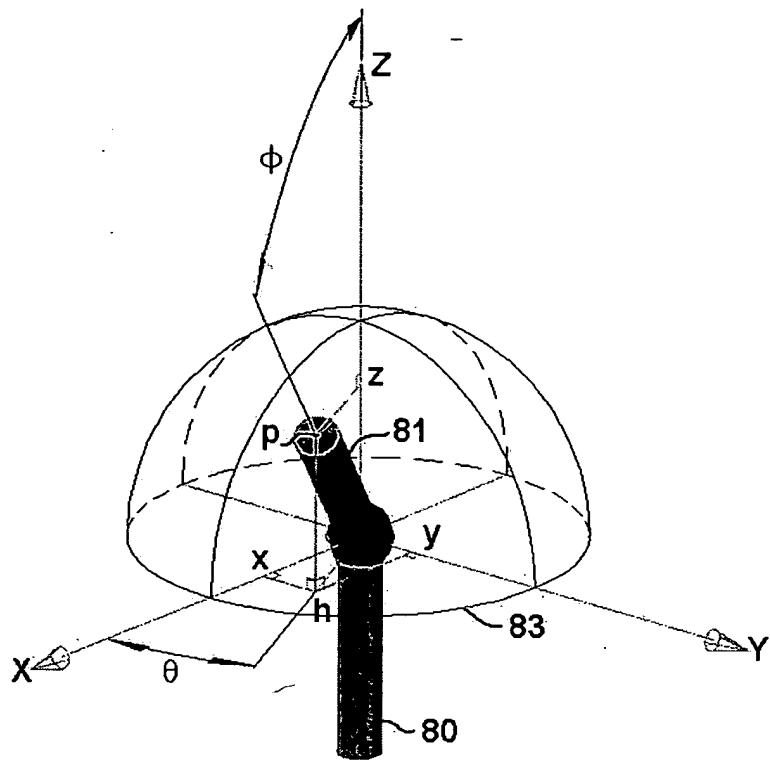


Figure 14

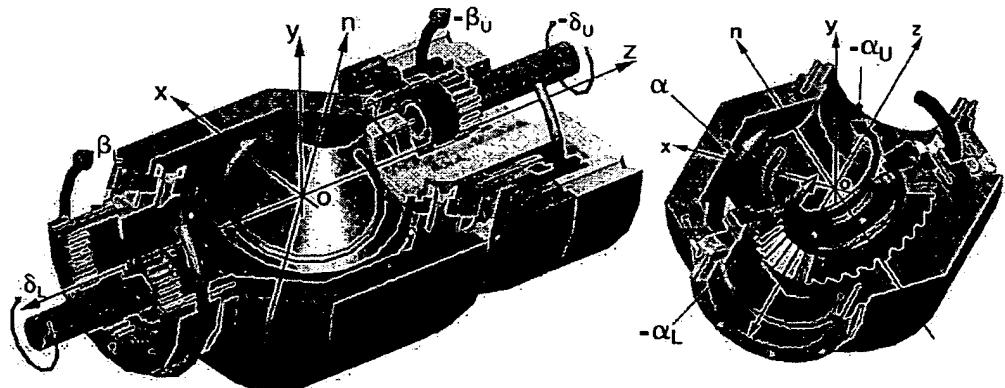


Figure 15a

Figure 15b

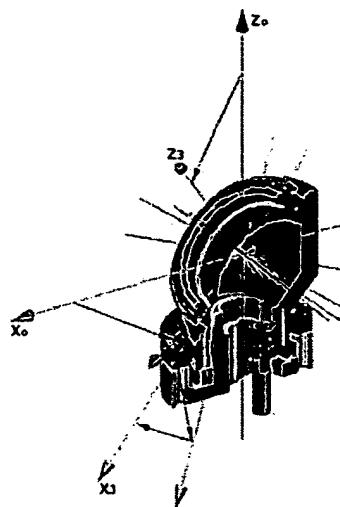


Figure 16a.

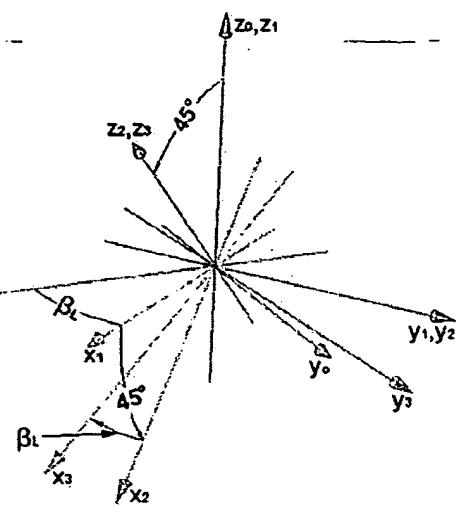


Figure 16b

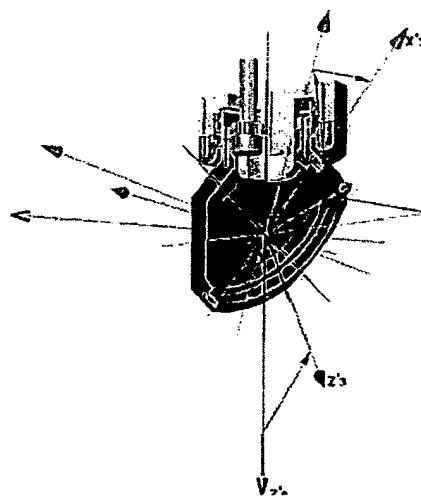


Figure 17a

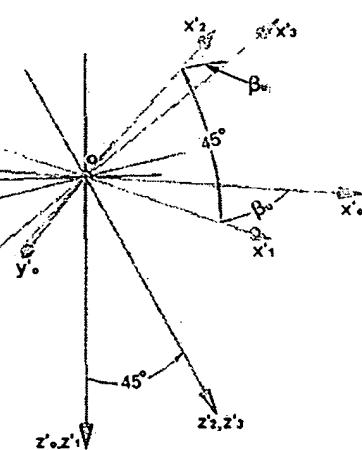


Figure 17b

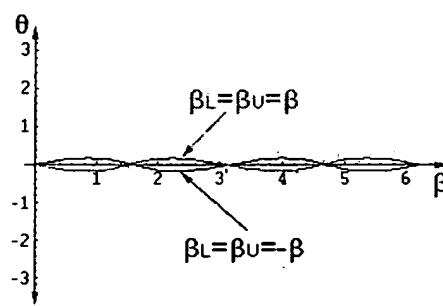


Figure 18a

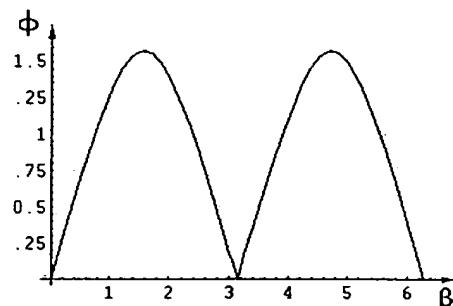


Figure 18b

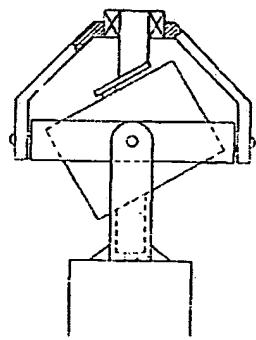


Figure 19a

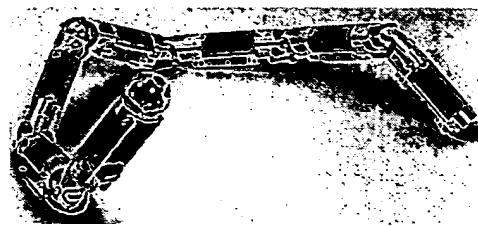


Figure 19b

PRIOR ART

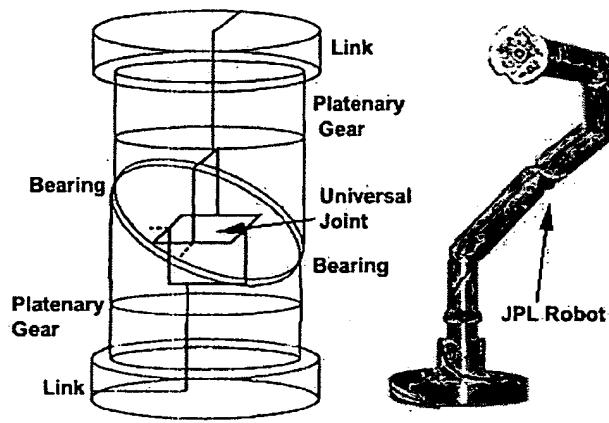


Figure 20a

Figure 20b

PRIOR ART

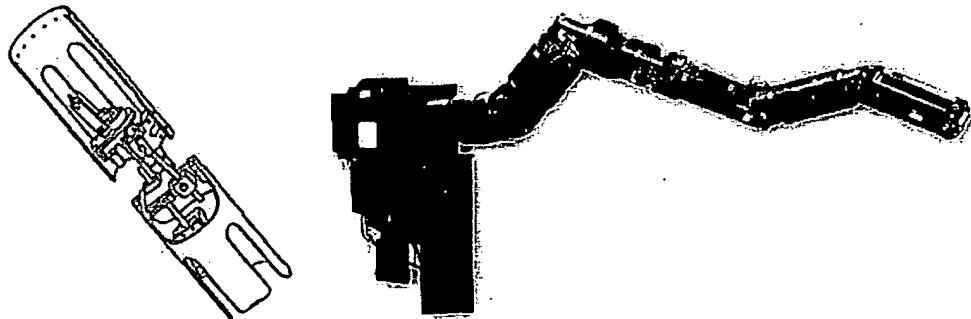


Figure 21a

PRIOR ART

Figure 21b

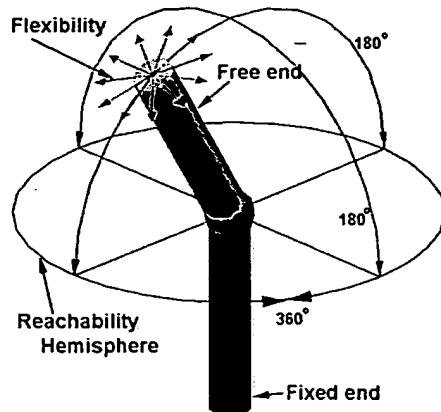


Figure 22

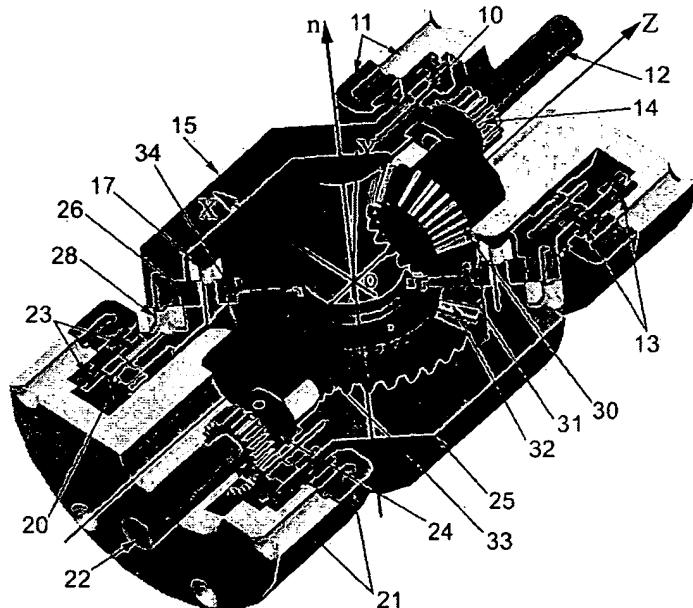


Figure 23

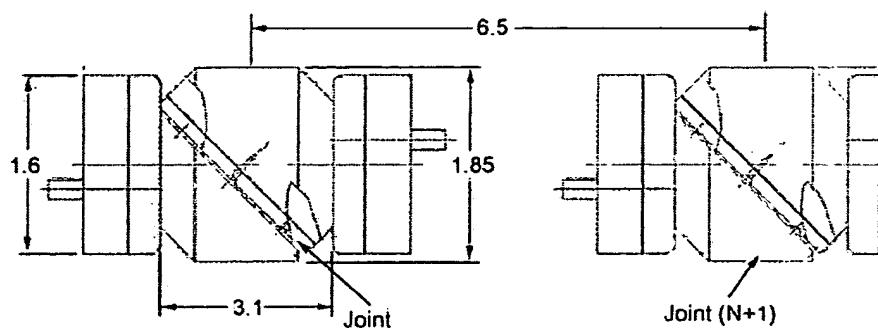


Figure 24

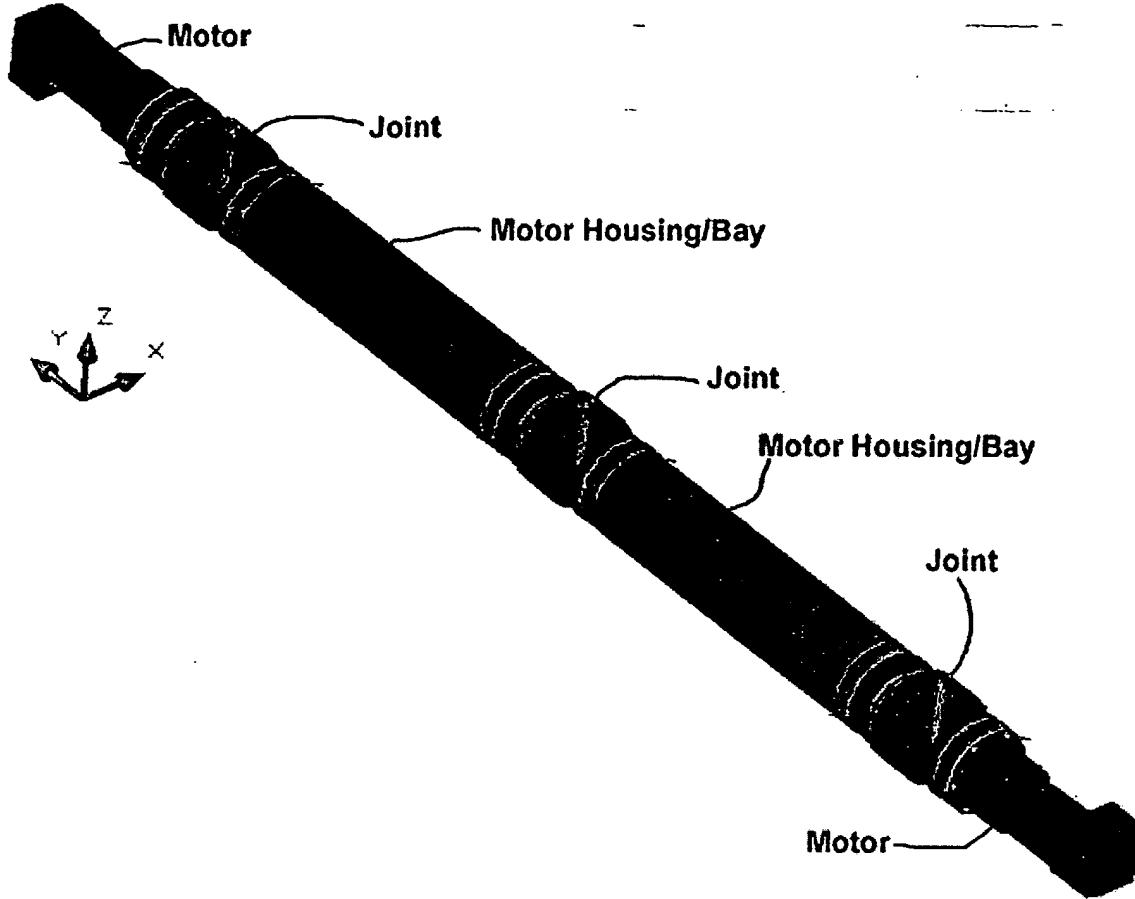


Figure 25.

Figure 25 shows part of a snake robot wherein motor housings / bays are connected together with joints of the present invention.